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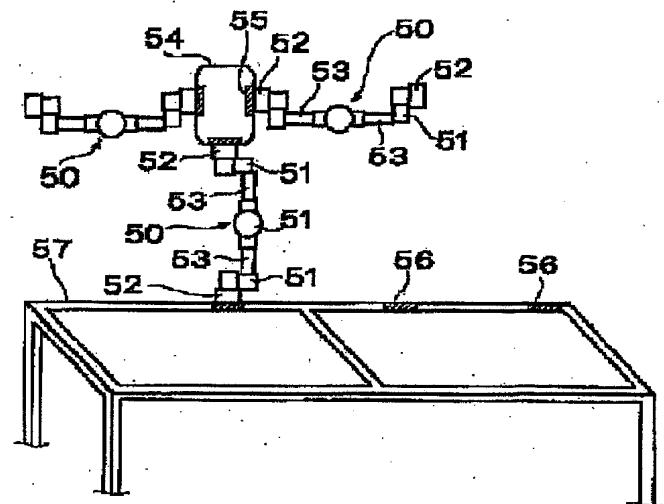
APPLICATION DATE : 21-12-98
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APPLICANT : NATL SPACE DEVELOPMENT
AGENCY OF JAPAN;

INVENTOR : OKAMI YOSHIAKI;

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TITLE : RECONFIGURATION TYPE SPACE
MULTIPLE MANIPULATOR SYSTEM



ABSTRACT : PROBLEM TO BE SOLVED: To provide a reconfiguration type space multiple manipulator system capable of reconfiguring a system as a small type multiple manipulator system capable of operating works in space.

SOLUTION: A three three leg manipulator system is so constituted as follows, three pieces of arms 50 in a link formation formed out of two booms 53 to which joint parts 51 are disposed, and of end effector 52 disposed to the other ends of the booms 53 via the joint parts 51, are combined with the combining ports 55 of a robot center part 54 via the end effector 52, and a distributed type control computer capable of carrying out the joint cooperation, an operation monitor, and the system management of an entire robot, including a joint driving circuit, a wireharness and a joint control, is disposed to the inside of each boom 53, and each end factor 52 is equipped with operating fingers, and TV cameras, connectors and the like.

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